In the Claims:

Claims 1-10 (Cancelled).

11. (Previously Presented) A method of automated pallet repair, comprising the steps of:

using a scanning device to create a three-dimensional data map of a pallet for detecting gaps and protrusions in the pallet, the scanning device generating a laser beam projected onto the pallet;

filtering the three-dimensional data map into a two-dimensional image of on/off values by using a dynamically created height value, corresponding to a reference plane or set threshold offset above a board surface of the pallet;

creating a recipe of repair operations from the three-dimensional data map; and

gripping the pallet and transporting the gripped pallet to one or more repair stations in accordance with the recipe.

Claim 12 (Cancelled).

13. (Previously Presented) The method of claim 11, further comprising filtering the three-dimensional data map with a Sobel or Gaussian filter to provide locations of the gaps and protrusions in the pallet.

Claims 14-16 (Cancelled).

17. (Previously Presented) A method of automated pallet repair, comprising the steps of:

using a scanning device to create a three-dimensional data map of a pallet for detecting gaps and protrusions in the pallet;

filtering the three-dimensional data map into a two-dimensional image of on/off values by using a dynamically created height value, corresponding to a reference plane or set threshold offset above a board surface of the pallet;

creating a recipe of repair operations from the three-dimensional data map; and

transporting the pallet to at least one repair station in accordance with the recipe.

18. (Previously Presented) The method of claim 17, further comprising filtering the three-dimensional data map with a Sobel or Gaussian filter to provide locations of the gaps and protrusions in the pallet.

19. (Previously Presented) The method of claim 17, wherein the scanning device generates a laser beam projected onto the pallet.

20. (Previously Presented) A method of automated pallet repair, comprising the steps of:

generating a map of a pallet, the map including features, dimensions and topography of the pallet;

generating a recipe of repair operations based on the map; and

transporting the pallet to at least one repair station based on the recipe.

21. (Previously Presented) The method of claim 20, wherein the map is generated using a scanning device, the scanning device generating a laser beam projected onto the pallet, and wherein the map comprises a three-dimensional data map.

22. (Previously Presented) The method of claim 21, further comprising filtering the three-dimensional data map into a two-dimensional image.

23. (Previously Presented) The method of claim 22, wherein the two-dimensional image comprises on/off values by using a dynamically created height value corresponding to a reference plane above a board surface of the pallet.

24. (Previously Presented) The method of claim 22, wherein the two-dimensional image comprises on/off values by using a dynamically created height value corresponding to set threshold offset above a board surface of the pallet.

25. (Previously Presented) The method of claim 21, further comprising filtering the three-dimensional data map with

a Sobel or Gaussian filter to provide locations of gaps and protrusions in the pallet.

26. (Previously Presented) The method of claim 20, further comprising gripping the pallet before transporting the pallet to the at least one repair station.